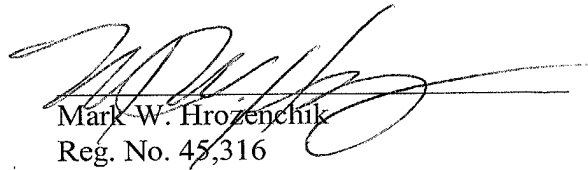


Prompt and favorable action is solicited.

Respectfully submitted,

  
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MARKED-UP VERSION

25. (Amended) A controller for controlling the acceleration of an armature of an electric drive, with means for generating a partly synthesized high quality acceleration error correction signal  $\underline{z}$ , comprising:

an accelerometer mechanically attached to the armature of the electric drive to measure a true armature acceleration  $\alpha$ , made available as a measured armature acceleration value  $\underline{b}_m$ , equal to the product of the true armature acceleration  $\alpha$  and an acceleration measurement transfer function  $F_g(p)$ , the acceleration measurement transfer function  $F_g(p)$  having a complex frequency variable  $p$  whereby the function [and being defined by the relationship]  $F_g(p)$  equals one when  $p$  equals 0;

means for measuring a substitute acceleration signal  $b_E$ , made available as a measured acceleration signal,  $\underline{b}_{Em}$ ;

means to scale the measured armature acceleration value  $\underline{b}_m$  and the measured acceleration signal  $\underline{b}_{Em}$  such that the relationship of  $\underline{b}_m = \alpha \cdot F_g(p) = \underline{b}_{Em} \cdot F_g(p)$  is satisfied;

a first filter for filtering the measured armature acceleration signal  $\underline{b}_m$  with a first filter transfer function of  $F_T(p)$ , to obtain a first filter output signal  $\underline{x} = \underline{b}_m \cdot F_T(p)$ , in which the first filter transfer function  $F_T(p)$  has the complex frequency variable  $p$  [and is further defined by the relationship  $F_T(p)$  equals one when  $p$  equals 0];

a second filter for filtering the measured acceleration signal  $\underline{b}_{Em}$  with a second filter transfer function of  $F_H(p)$ , to obtain a second filter output signal  $\underline{y} = \underline{b}_{Em} \cdot F_H(p)$ ; and

means for combining the first and second filter outputs to form the partly synthesized high quality acceleration error correction signal  $\underline{z} = \underline{b}_m \cdot F_T(p) + \underline{b}_{Em} \cdot F_H(p)$ .

40. (New) The controller according to claim 25, wherein the function  $F_T(p)$  equals one when  $p$  equals 0.